

## CLAIMS

1. A robot adapted to operate in association with an interface surface having disposed therein or thereon coded data indicative of a plurality of reference points of the interface surface, the robot comprising:  
movement means to allow the robot to move over the interface surface;  
5 a sensing device which senses at least some of the coded data and generates indicating data indicative of a position of the robot on the interface surface;  
communication means to transmit the indicating data to a computer system running a computer application, and to receive movement instructions from the computer application; and,  
a marking device adapted to selectively mark the interface surface in response to marking  
10 instructions received from the computer application.
2. The robot as claimed in claim 1, wherein the marking device is at least one pen, or the like, attached to or held by the robot.
- 15 3. The robot as claimed in claim 1, wherein the marking device is at least one printhead attached to or held by the robot.
4. The robot as claimed in claim 1, wherein the marking device can be selectively moved into and out of contact with the interface surface.  
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5. The robot as claimed in claim 1, wherein a characteristic of the marking device is determined by the robot decoding a barcode on the marking device.
6. The robot as claimed in claim 1, wherein a characteristic of the marking device is determined by the  
25 robot reading a value from a solid-state memory associated with the marking device.
7. The robot as claimed in claim 1, wherein a characteristic of the marking device is determined by a user activating a hyperlink on the interface surface using the robot.
- 30 8. The robot as claimed in claim 7, wherein a characteristic of the marking device is the color of the ink in the marking device.
9. The robot as claimed in claim 1, wherein the robot can operate in a raster mode or a vector mode.
- 35 10. The robot as claimed in claim 1, wherein the robot can be remotely controlled by a user.
11. The robot as claimed in claim 1, wherein the movement means are electronically driven wheels.

12. The robot as claimed in claim 1, wherein the computer application controls the marking device in response to the indicating data received by the computer system.

5 13. The robot as claimed in claim 1, wherein the robot has a unique robot identifier which is adapted to distinguish the robot from other robots.

14. The robot as claimed in claim 1, wherein the indicating data is transmitted to the computer system by a wireless signal.

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15. The robot as claimed in claim 14, wherein the computer system is adapted to receive the indicating data via a relay device in wireless communication with the robot.

16. The robot as claimed in claim 1, wherein the interface surface is a netpage.

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17. The robot as claimed in claim 1, wherein the coded data is also indicative of an identity of the interface surface that can be sensed by the sensing device.

18. A system for marking an interface surface by controlling a robot provided with means to mark the interface surface, the system comprising:

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the interface surface, having disposed therein or thereon coded data indicative of a plurality of reference points of the interface surface, thereby facilitating the robot to operate in association with the interface surface;

25 the robot, provided with movement means to allow the robot to move over the interface surface, and a sensing device which senses at least some of the coded data and generates indicating data indicative of a position of the robot on the interface surface, and a marking device adapted to mark the interface surface; and,

30 a computer system running a computer application, the computer system in communication with the robot, the computer application adapted to receive the indicating data and to transmit movement instructions and marking instructions to the robot.

19. A method of marking an interface surface by controlling a mobile robot adapted to mark the interface surface, the robot additionally adapted to operate in association with the interface surface having disposed therein or thereon coded data indicative of a plurality of reference points of the interface surface, the method including the steps of:

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the robot sensing at least some of the coded data and generating indicating data indicative of a position of the robot on the interface surface;

the robot transmitting the indicating data to a computer system running a computer application;

the robot receiving movement instructions from the computer application; and,

5           the robot receiving marking instructions from the computer application to selectively mark the interface surface.

20.       The method as claimed in claim 19, wherein the robot can mark the interface surface while stationary or moving.

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